The listing of claims will replace all prior versions, and listings, of claims in this application:

Listing of Claims:

1. (currently amended) ~~Controller with~~ A controller comprising three parallel arms (2) connecting a base (1) to a platform (3) carrying grasping means such as a handle (4), ~~characterized in that~~ the arms ~~are made up of~~ comprising three links (5,6,7) of which a first link (5) is joined to the base by a first joint (8) which is a pivot joint of the first link about itself, a second link (6) joined to the first link (5) by a second joint (9) which is a rotation joint to modify an angle between the first link and the second link, a third link (7) joined to the platform (3) by a ball-joint (11) and to the second link (6) by a third joint (10) which is a rotation joint to modify an angle between the second link and the third link, ~~and in that~~ wherein each of the arms only comprise two force feedback motors (16,23), of which a first motor (16) fixed to the base (1,12) and measuring pivot movements of the first link (5) and a second motor (23) positioned on the second joint (6) and measuring the rotations between the first link and the second link.

2. (currently amended) ~~Controller~~ The controller as in claim 1, ~~characterized in that~~ wherein the first links (5) are implanted on the base (1,12) in diverging directions.

3. (currently amended) ~~Controller~~ The controller as in claim 2, ~~characterized in that~~ wherein the first links (5) are implanted on the base (1,12) at an incline of ~~around~~ 40° relative to a ~~normal of~~ direction perpendicular to the base.

4. (new) A controller consisting of a base, a platform carrying grasping means such as a handle (4), three parallel arms (2) connecting a base (1) to the platform (3) and six force

feedback motors, the arms comprising three links (5,6,7) of which a first link (5) is joined to the base by a first joint (8) which is a pivot joint of the first link about itself, a second link (6) joined to the first link (5) by a second joint (9) which is a rotation joint to modify an angle between the first link and the second link, a third link (7) joined to the platform (3) by a ball-joint (11) and to the second link (6) by a third joint (10) which is a rotation joint to modify an angle between the second link and the third link, wherein each of the arms comprises two force feedback motors (16,23), of which a first motor (16) fixed to the base (1,12) and measuring pivot movements of the first link (5) and a second motor (23) positioned on the second joint (6) and measuring the rotations between the first link and the second link.

5. (new) The controller as in claim 1, wherein the first links (5) are implanted on the base (1,12) in diverging directions.

6. (new) The controller as in claim 2, wherein the first links (5) are implanted on the base (1,12) at an incline of 40° relative to a direction perpendicular to the base.